

EAST Search History

Ref #	Hits	Search Query	DBs	Default Operator	Plurals	Time Stamp
L1	294	(703/7).CCLS.	USPAT; USOCR	OR	OFF	2006/06/14 10:22
L2	225	I1 and simulat\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 10:22
L3	25	I2 and dynamic\$2 and kinematic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 10:23
L4	16	("5576727" "5625576" "5642469" "5754023" "5802353" "5880714" "5898599" "5987454" "6005551" "6046563" "6046727" "6075475" "6084587" "6111577" "6131097" "6283859").PN. OR ("7027965").URPN.	US-PGPUB; USPAT; USOCR	OR	ON	2006/06/14 10:51
L5	483	((700/25) or (700/28)).CCLS.	USPAT; USOCR	OR	OFF	2006/06/14 10:52
L6	151	I5 and simulat\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 10:52
L7	24	I6 and hybrid	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 10:52
L9	17	I7 and dynamic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:07
L10	997	((345/653) or (345/659) or (345/473)).CCLS.	USPAT; USOCR	OR	OFF	2006/06/14 11:07
L11	408	I10 and simulat\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:07
L12	37	I11 and dynamic\$2 and kinematic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:08
L13	4	I11 and dynamic\$2 and kinematic\$2 and hybrid	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:14
L14	137	(368/229).CCLS.	USPAT; USOCR	OR	OFF	2006/06/14 11:14

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L15	15	l14 and simulat\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:15
L16	10	l14 and dynamic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:15
L17	56	simulat\$5 same hybrid same three\$dimension\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:16
L18	16	simulat\$5 same hybrid same three\$dimension\$2 same dynamic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:17
L19	426	simulat\$5 same kinematic\$2 and dynamic\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:18
L20	129	simulat\$5 same kinematic\$2 and dynamic\$2 and geometric\$3 and (animat\$3 or motion\$2)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:19
L22	64	simulat\$5 same kinematic\$2 and dynamic\$2 and geometric\$3 and (animat\$3 or motion\$2) and transition	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:19
L23	46	simulat\$5 same kinematic\$2 and dynamic\$2 and geometric\$3 and (animat\$3 or motion\$2) and transition and rotat\$3 and displac\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:25
L24	2297	hybrid same simulat\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:25
L25	40	hybrid same simulat\$5 and (dynamic and kinematic\$2)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:26

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L26	40	hybrid same simulat\$5 and (dynamic\$2 and kinematic\$2)	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:26
L28	13	hybrid same simulat\$5 and (dynamic\$2 and kinematic\$2) and transition	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:28
L29	72	(dynamic\$2 and kinematic\$2) same simulat\$5 and transition	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:28
L30	40	(dynamic\$2 and kinematic\$2) same simulat\$5 and transition and table	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:28
L31	33	(dynamic\$2 and kinematic\$2) same simulat\$5 and transition and table and variable\$2	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:28
L32	25	(dynamic\$2 and kinematic\$2) same simulat\$5 and transition and table and variable\$2 and rotat\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:29
L33	20	(dynamic\$2 and kinematic\$2) same simulat\$5 and transition and table and variable\$2 and rotat\$3 and displace\$5	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 11:56
L34	12	simulat\$5 same hybrid same electromechanic\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 12:01
L35	7	test\$3 same debug\$4 same electro\$mechanic\$3	US-PGPUB; USPAT; USOCR; EPO; JPO; DERWENT; IBM_TDB	OR	ON	2006/06/14 12:02
L36	1	("5754023").PN.	USPAT; USOCR	OR	OFF	2006/06/14 12:25
S1	1	("5831853").PN.	USPAT; USOCR	OR	OFF	2006/06/14 10:22



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<u>#3</u>	(((simulation and hybrid and electromechanic)<in>metadata)) <and> (pyr >= 1950 <and> pyr <= 2003)		0
<u>#4</u>	(((debugging and testing and electromechanic)<in>metadata)) <and> (pyr >= 1950 <and> pyr <= 2003)		0
<u>#5</u>	(((hybrid and dynamic and kinematic)<in>metadata)) <and> (pyr >= 1950 <and> pyr <= 2003)		30
<u>#6</u>	(((hybrid and dynamic and kinematic)<in>metadata)) <and> (pyr >= 1950 <and> pyr <= 2003)		30
<u>#7</u>	(((hybrid and dynamic and kinematic)<in>metadata)) <and> (pyr >= 1950 <and> pyr <= 2003)		30
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<u>#11</u>	(((hybrid and dynamic and kinematic)<in>metadata)) <and> (pyr >= 1950 <and> pyr <= 2003)		30
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- ☐ 1. [Flight Simulation Software at NASA Dryden Flight Research Center](#) [PDF-56K]
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...Flight Research Center. **Simulation** benefits all phases...systems design and **testing**, and flight test support...envelope expansion. A **simulation** laboratory was established...support ground and flight **testing** of advanced research...relies extensively on **simulation** to support development...
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- ☐ 3. [Techniques for the Design and Simulation of Running Robots](#) [PDF-460K]
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Techniques for the Design and **Simulation** of Running Robots by John Robert Ridgely...Berkeley 2001 Techniques for the Design and **Simulation** of Running Robots Copyright 2001 by...Abstract Techniques for the Design and **Simulation** of Running Robots by John Robert Ridgely...
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...an algorithmic **debugging** framework for...Generalized Algorithmic **Debugging** and **Testing** method (GADT...valued and make the **simulation** models behave...associated to the **electromechanical** device **simulation** example is given...
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 ...automotive mechatronic systems, robotics, machine vision, experimental stress analysis, heat trans- fer, fluid flow, system **simulation**, circuits and communications, control, mechanical and electrical properties of materials, solid- state devices and microelectronics...
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- ❑ 6. [ALGEMENE INLIGTING:](#) [PDF-357K]
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[\[http://www.up.ac.za/yearbook/2002/Engineering2002.pdf\]](http://www.up.ac.za/yearbook/2002/Engineering2002.pdf)
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 Laboratory experiments and lectures focus on a design and construction project, such as an autonomous moving vehicle. Prerequisites: Credit or registration in either Math 120 oe Calculus and Analytic Geometry, I., or Math 135 oe Calculus.
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 3 A Message from the Dean
 4 Henry Samueli School of Engineering and Applied Science
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- ❑ 10. [Simulation and construction of a speed control for a DC series motor](#)
Santana, J. / Naredo, J.L. / Sandoval, F. / Grout, I. / Argueta, O.J.,
Mechatronics, Nov 2002
 ...other developments. The **simulations** have permitted the **testing** and the **debugging** of the speed control...constructed. For instance, the **simulations** have helped to establish...costs substantially. The **simulations**, when combined with experimental...
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 ...executive and control mechanisms, and computer maintenance schemes:
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... Student Success Center · Placement **Testing** · Orientation 29 Fees and
Financial Aid...International Programs · 351.3127 CLEP **Testing** · 351.3594
Clubs and Organizations ·...Personnel, Staff · 351.3420 Placement **Testing** ·
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...from First Principles.....
48 2.3.6 Qualitative

Simulation

51 2.4 FAILURE CONTROL AND CORRECTION...

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healing, wholeness, and abundant living Editors Dr. Debra Sowell, Dean of
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Jan 2000

Testing Embedded-Core Based System Chips Yervant Zorian
LogicVision...challenges. Section 3 presents a conceptual architecture for
testing such system chips, consisting of three structural elements...Test
Challenges In this section, the main challenges of **testing** system chips are
analyzed and compared to the traditional...

[<http://www.ra.informatik.uni-stuttgart.de/~rainer/Lite...>]

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☐ **16. TABLE OF CONTENTS** [PDF-58K]

Jan 2002

...EASY5. On-line interactive **debugging** tools are available between the user
and the **simulation** math models. Applications include laboratory design,
testing, and rapid prototyping of...prototype ECU to a real-time **simulation** of
the plant such that it...digital interface between the **simulation** computer and
ECU. Typical...

[http://0-ewh.ieee.org.csulib.ctstateu.edu/r4/se_michig...]

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☐ **17. Monitoring, testing and debugging of distributed real-time systems**

Thane, Henrik, Jan 2000

...Thane, Henrik Title: Monitoring, **testing** and **debugging** of distributed real-
time systems...real-time systems. Keywords Monitoring, **testing**, **debugging**,
testability, distributed real-time...natural reasons led me to also consider
testing, **debugging** and monitoring. That work gave fruit...

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...teamwork, written and oral communication skills, and uses computer tools (Electronic Workbench and MATLAB) for analysis and **simulation**. EGR 131 1 credit Introduction to Design .5 hours lecture, 1.5 hours laboratory For students not in the IMPULSE program, covers...

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Faculty of Engineering 2001 HANDBOOK Courses, programs and any arrangements for programs including staff allocated as stated in this Handbook are an expression of intent only. The University reserves the right to discontinue or vary arrangements at any time without notice.

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Testing.....

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Hybrid current-controlled VSI-IM drive

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Z Cucej, P Cafuta, R Sveclo - Advanced Motion Control, 2004 8th IEEE International ..., 2004 - ieeexplore.ieee.org

... responsible for the tracking of drive **kinematic** variables and ... Roughly, the **dynamics** of **HCC** are as follows, see ... assumed to start in a certain **hybrid** state, say ...

[Web Search](#)

Simulation of a Rover and Display in a Virtual Environment - group of 3 »

A Sweet, T Blackmon, V Gupta - Proc. of the American Nuclear Society 8th International ..., 1999 - stratify.com

... implementing a simple set of **kinematics** and **dynamics** ... including the rigid-body **dynamics**, power systems ... **Hybrid** CC and interval constraints." Proceedings of ...

Cited by 3 - [View as HTML](#) - [Web Search](#)

Use of hybrid models for testing and debugging control software for electromechanical systems

K Kondo, M Yoshida - Mechatronics, IEEE/ASME Transactions on, 2005 - ieeexplore.ieee.org

... with a three- dimensional **kinematics** simulator and a ... and A. Courtois, "Using **hybrid** concurrent constraint programming to model **dynamic** biological systems ...

[Web Search](#)

A local coordinate system for assumed strain shell element formulation - group of 2 »

HCC Park, SWC Lee - Computational Mechanics, 1995 - Springer

... Lee and Nan (1978) introduced the assumed strain **hybrid** formulation based on the ... excessively simple assumed strain field may trigger spurious **kinematic** modes. ...

Cited by 6 - [Web Search](#)

[PS] Model-enabled control of hybrid systems - group of 2 »

S McIlraith, G Biswas, M Fromherz, J Howe, R Fikes ... - 1998 - ksl.stanford.edu

... intents of neighboring aircraft, and **kinematic** models to ... modeling and analysis of **hybrid dynamic** physical systems ... by the declarative **hybrid** modeling, simulation ...

Cited by 3 - [View as HTML](#) - [Web Search](#)

Impedance control for articulated robot of 6 degree-of-freedom inconsideration of critically damped ... - group of 2 »

F Nagata, K Watanabe, K Sato, K Izumi, T Suehiro - SICE'97. Proceedings of the 36th SICE Annual Conference. ..., 1997 - ieeexplore.ieee.org

... Recently **Hybrid** ComplianceForce Control (**HCC**) methods4) were proposed ... Impedance Control From (I), the **dynamic** equation for a ... the same way as **HCC**, considering a ...

Cited by 7 - [Web Search](#) - [BL Direct](#)

[book] Simulating and Generating Motions of Human Figures - group of 2 »

K Yamane - 2004 - books.google.com

... A foundation for **dynamic** modeling of complex **kinematic** chains is established and original methods for interactive generation of human figure motions are ...

Cited by 3 - [Web Search](#) - [Library Search](#)

MBO (N) D: A multibody method for long-time molecular dynamics simulations - group of 2 »

HM Chun, CE Padilla, DN Chin, M Watanabe, VI ... - Journal of Computational Chemistry, 2000 - doi.wiley.com

... This results in the use of larger integration step sizes, substantially reducing the computational time required for a given **dynamic** simulation. ...

[Cited by 22](#) - [Web Search](#) - [BL Direct](#)

An Experiment on Force Control Using Fuzzy Environment Models

F Nagata, K Watanabe, K Sato, K Izumi, S Akama - Procs. of the 4th International Symposium on ArtificialLife ..., 1999 - [fmv5.fitc.pref.fukuoka.jp](#)

... Forward **Kinematics** ... ASME Journal of **Dynamic** Systems, Measurement and Control, vol. ...

K. Ioi, N. Kubota and O. Noro: Application of **Hybrid** Compliance/Force Control ...

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Investigating the Reaction Dynamics of Dicarbon Molecules, C

X Gu, Y Guo, AM Mebel, RI Kaiser - Molecules - [chem.hawaii.edu](#)

... These **dynamics** result in forward-scattered contour plots of the heavy ... C 3 H radical and about 25 % more abundant than the ethynyl radical (**HCC**; $X^2\Sigma^+$). ...

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[Impedance control for articulated robot of 6 ...](#) - by Nagata - 7 citations

[Model-enabled control of hybrid systems](#) - by McIlraith - 3 citations

[Simulation of a Rover and Display in a Virtual Environment](#) - by Sweet - 3 citations

[PDF] Simulation of a Rover and Display in a Virtual Environment ...

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simplified **kinematics** and **dynamics** for the rover, in order to test the software ... An **HCC** simulation is first created as a text file with the model to be ...

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Earthquake Physics: Seismicity and Source Process Posters ...

The results from Model A and B are consistent with **kinematic** rupture model. ... Alaska (Mw=7.9) Using **Hybrid** Blind Deconvolution Method Boi-Yee Liao and ...

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